
The synthesis of control actions to drive the actuators of walking robots without solving the inverse kinematics task

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The paper describes an approach to the synthesis of control actions for walking robots drives, eliminating the need for solving the inverse kinematics task. It outlines the preconditions approach. On the example of a four-legged walking mechanism the practical application of the approach is shown. The results of this approach for the case of a rectilinear and rectilinear “cautious” movements are presented. Some particular cases of this approach are specified.

Keywords: walking robot, the algorithm, kinematics, approach, trajectory, inverse task, simulation, cycle.

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